

Amendments to the Claims:

This listing of claims will replace all prior versions, and listings, of claims in the application:

Listing of Claims:

1. (Canceled)
2. (Currently Amended) ~~The method of claim 1, further comprising: A~~
method of determining a noise-corrected power delay profile, the method comprising:
determining a power delay profile;
calculating a noise-corrected power delay profile, wherein the step of
calculating the noise-corrected power delay profile comprises using a biased noise-floor
power estimate, the power delay profile, and a noise-scaling factor; and
calculating a center-of-gravity position estimate[[: and]], wherein the step of
calculating the center-of-gravity position estimate comprises using the noise-corrected
power delay profile.
3. (Currently Amended) The method of claim [[1]] 2, wherein the noise-
scaling factor is applied to the noise-floor power estimate.
4. (Currently Amended) The method of claim [[1]] 2, wherein the noise-
scaling factor is dependent upon a probability density function.
5. (Currently Amended) The method of claim [[1]] 2, wherein:
the step of determining the power delay profile comprises using a first
plurality of values; and
the step of calculating the noise-corrected power delay profile comprises
using the first plurality of values and a second plurality of values.

6. (Original) The method of claim 5, wherein:
the first plurality of values is a plurality of power-delay-profile values N_p ;
and
the second plurality of values is the N_n smallest power-delay-profile values.

7. (Original) The method of claim 6, wherein the noise-scaling factor is dependent upon a probability density function of the biased noise-floor power estimate.

8. (Original) The method of claim 2, wherein:

Z is the biased noise-floor power estimate;

τ_k is a time delay;

γ is the noise-scaling factor;

h_k is a plurality of power values;

N_p is a plurality of the plurality of power values h_k ; and

the center-of-gravity position estimate is
$$\frac{\sum_{k=1}^{N_p} \tau_k (h_k - \gamma Z)}{\sum_{k=1}^{N_p} (h_k - \gamma Z)}.$$

9. (Currently Amended) The method of claim [[1]] 2, wherein:

Z is the biased noise-floor power estimate;

γ is the noise-scaling factor;

h_k is a plurality of power values; and

the noise-corrected power delay profile is $h_k - \gamma Z$.

10. (Currently Amended) The method of claim [[1]] 2, wherein:

σ_n^2 is the biased noise-floor power estimate;

Z^* is a mean power of a plurality of values h_k ;

γ is the noise-scaling factor; and

$$\gamma = \frac{Z^*}{\sigma_g^2}.$$

11. (Currently Amended) The method of claim [[1]] 2, wherein:
 γ' is the noise-scaling factor;

$$\gamma' = \frac{N_{paths} + \gamma(N_p - N_{paths})}{N_p};$$

N_p is a plurality of power values;

N_{paths} is a number of true paths among the N_p power values

σ_g^2 is the biased noise-floor power estimate;

Z^* is a mean power of a plurality of power values N_n ; and

$$\gamma = \frac{Z^*}{\sigma_g^2}.$$

12. (Original). The method of claim 2, further comprising:
determining the noise-scaling factor;
storing the noise-scaling factor for on-line use; and
wherein the step of determining the noise-scaling factor is performed offline and
before the steps of determining the power delay profile, calculating the noise-corrected
power delay profile, and calculating the center-of-gravity position estimate.

13. (Original) An apparatus for determining a noise-corrected power delay
profile, the apparatus comprising:
a channel estimator;
a despreader; and
a delay estimator interoperably connected to the channel estimator and the
despreader, the delay estimator for:
determining a power delay profile;
calculating a noise-corrected power delay profile; and

wherein the step of calculating the noise-corrected power delay profile comprises using a biased noise-floor power estimate, the power delay profile, and a noise-scaling factor.

14. (Original) The apparatus of claim 13, wherein the delay estimator is further for:

calculating a center-of-gravity position estimate; and

wherein the step of calculating the center-of-gravity position estimate comprises using the noise-corrected power delay profile.

15. (Original) The apparatus of claim 13, wherein the noise-scaling factor is applied to the biased noise-floor power estimate.

16. (Original) The apparatus of claim 13, wherein the noise-scaling factor is dependent upon a probability density function.

17. (Original) The apparatus of claim 13, wherein:
the step of determining the power delay profile comprises using a first plurality of values; and
the step of calculating the noise-corrected power delay profile comprises using the first plurality of values and a second plurality of values.

18. (Original) The apparatus of claim 17, wherein:
the first plurality of values is a plurality of power-delay-profile values N_p ;
and
the second plurality of values is the N_n smallest power-delay-profile values.

19. (Original) The apparatus of claim 18, wherein the noise-scaling factor is dependent upon a probability density function of the biased noise-floor power estimate.

20. (Original) The apparatus of claim 14, wherein:

Z is the biased noise-floor power estimate;

τ_k is a time delay;

γ is the noise-scaling factor;

h_k is a plurality of power values;

N_p is a plurality of the plurality of power values h_k ; and

the center-of-gravity position estimate is
$$\frac{\sum_{k=1}^{N_p} \tau_k (h_k - \gamma Z)}{\sum_{k=1}^{N_p} (h_k - \gamma Z)}.$$

21. (Original) The apparatus of claim 13, wherein:

Z is the biased noise-floor power estimate;

γ is the noise-scaling factor;

h_k is a plurality of power values; and

the noise-corrected power delay profile is $h_k - \gamma Z$.

22. (Original) The apparatus of claim 13, wherein:

σ_k^2 is the biased noise-floor power estimate;

Z^* is a mean power of a plurality of values h_k ;

γ is the noise-scaling factor; and

$$\gamma = \frac{Z^*}{\sigma_k^2}.$$

23. (Original) The apparatus of claim 13, wherein:

γ' is the noise-scaling factor;

$$\gamma' = \frac{N_{paths} + \gamma(N_p - N_{paths})}{N_p};$$

N_p is a plurality of power values;

N_{paths} is a number of true paths among the N_p power values

σ_k^2 is the biased noise-floor power estimate;

Z^* is a mean power of a plurality of power values N_n ; and

$$\gamma = \frac{Z^*}{\sigma_k^2}.$$

24. (Original) The apparatus of claim 14, further comprising:

determining the noise-scaling factor;

storing the noise-scaling factor for on-line use; and

wherein the step of determining the noise-scaling factor is performed offline and before the steps of determining the power delay profile, calculating the noise-corrected power delay profile, and calculating the center-of-gravity position estimate.

25. (Canceled)

26. (Currently Amended) ~~The article of manufacture of claim 25,~~ An article of manufacture for determining a noise-corrected power delay profile, the article of manufacture comprising:

at least one computer readable medium; and

processor instructions contained on the at least one computer readable medium, the processor instructions configured to be readable from the at least one computer readable medium by at least one processor and thereby cause the at least one processor to operate as to:

determine a power delay profile;

calculate a noise-corrected power delay profile; and

wherein the calculation of the noise-corrected power delay profile comprises using a biased noise-floor power estimate, the power delay profile, and a noise-scaling factor;

wherein the processor instructions are further configured to cause the at least one processor to operate as to:

calculate a center-of-gravity position estimate; and

wherein the calculation of the center-of-gravity position estimate comprises

using the noise-corrected power delay profile.